Author Index to Volume 4

Ahmad, S., and Feddema, J. T.: Static Grip Selection for Robot-Based Automated Assembly Systems, 687
Al-Abbass, F.: See Özguner, Ü.
Ang, M. H., Jr., and Tourassis, V. D.: General-Purpose Inverse Kinematics Transformations for Robotic Manipulators, 527

Batchelor, B. G.: Editorial, 1
Bayo, E.: A Finite-Element Approach to Control the End-Point Motion of a Single-Link Flexible Robot, 63
—, and Paden, B.: On Trajectory Generation Shape by a Robotic Probe, 237
Cash, C.: See Wilhelm, W. E.
Chirco, A. I.: See Klein, C. A.

Driels, M. R., and Pathre, U. S.: Generalized Joint Model for Robot Manipulator Kinematic Calibration and Compensation, 77
—, and Pathre, U. S.: Robot Manipulator Kinematic Compensation Using a Generalized Jacobian Formulation, 259

Feddema, J. T.: See Ahmad, S.

Goddard, R. E.: See Hemami, H.
Goldenberg, A. A.: See Payandeh, S.
Gupta, K. C.: See Mirman, C. R.
Guthmiller, W. A.: See Ruokangas, C. C.

Hara, S.: See Omata, T.
Hemami, H., and Goddard, R. E.: Recognition of Geometrical Shape by a Robotic Probe, 237

Ishii, M., Sakane, S., Kakikura, M., and Mikami, Y.: A New Approach to Improve Absolute Positioning Accuracy of Robot Manipulators, 145

Kakikura, M.: See Ishii, M.
Kalkunte, M.: See Wilhelm, W. E.
Kim, C. E., and Langston, M. A.: Movement Coordination for Single-Track Robot Systems, 49
Klein, C. A., and Chirco, A. I.: Dynamic Simulation of a Kinematically Redundant Manipulator System, 5

Langston, M. A.: See Kim, C. E.
Lanzo, M.: See Luo, R. C.
Lau, K.: See Vira, N.
Leahy, M. B., Jr., Nugent, L. M., Saridis, G. N., and Valavanis, K. P.: Efficient PUMA Manipulator Jacobian Calculation and Inversion, 185
Lee, J. M. F.: See Ruokangas, C. C.
Levinson, D. A.: Comment on "Computer Generation of Robot Dynamics Equations and the Related Issues," by J. Koplik and M. C. Leu, 183
Lin, M. -L.: See Luo, R. C.
Litvin, F. L., Parenti Castelli, V., and Shaheen, M.: Singularities in Motion and Displacement Functions for a 7 Degree-of-Freedom Manipulation, 397
Low, K. H.: A Systematic Formulation of Dynamic Equations for Robot Manipulators with Elastic Links, 435

Luo, R. C.: Microcomputer-Based Robot Dynamic Sensing Using Linear Array Sensor for Object Recognition and Manipulation, 199
—, and Lin, M. -L.: Issues and Approaches of Automatic Focusing Algorithms for Intelligent Robot Eye-in-Hand System, 459
—, Scherp, R. S., and Lanzo, M.: Object Identification Using Automated Decision Tree Construction Approach for Robotics Applications, 423

McNeela, M. A.: See Thakor, N. V.
Mikami, Y.: See Ishii, M.
Mirman, C. R., and Gupta, K. C.: Robot Trajectory Planning Using the Convolution Operator, 605
Muir, P. F., and Neuman, C. P.: Kinematic Modeling of Wheeled Mobile Robots, 281
Murray, J. J.: See Neuman, C. P.
—: See Neuman, C. P.

Nakano, M.: See Omata, T.
Neuman, C. P.; See Muir, P. F.
—, and Murray, J. J.: Customized Computational Robot Dynamics, 503
—, and Tourassis, V. D.: Robust Discrete Nonlinear Feedback Control for Robotic Manipulators, 115
—, and Murray, J. J.: Symbolically Efficient Formulations for Computational Robot Dynamics, 743
Nevins, J. L.: Information-Control Aspects of Sensor Systems for Intelligent Robotics, 215
Nugent, L. M.: See Leahy, M. B., Jr.

Omata, T., Hara, S., and Nakano, M.: Nonlinear Repetitive Control with Application to Trajectory Control of Manipulators, 631
Orin, D. E.: See Tsai, Y. T.
Özguner, Ü., Yurkovich, S., and Al-Abbass, F.: Decentralized Variable Structure Control of a Two-Arm Robotic System, 377

Paden, B.: See Bayo, E.
Pandita, S.: See Tzou, H. S.
Parenti Castelli, V.: See Litvin, F. L.
Pathre, U. S.: See Driels, M. R.
—: See Driels, M. R.
Payandeh, S., and Goldenberg, A. A.: Formulation of the Kinematic Model of a General (6 DOF) Robot Manipulator Using a Screw Operator, 771
Pierson, B. L.: See Ruokangas, C. C.

Roukangas, C. C., Guthmiller, W. A., Pierson, B. L., Sliwinski, K. E., and Lee, J. M. F.: Off-Line Programming Motion and Process Commands for Robotic Welding of Space Shuttle Main Engines, 355

Sakane, S.: See Ishii, M.
Saridis, G. N.: See Leahy, M. B., Jr.
Scherp, R. S.: See Luo, R. C.
Seraji, H.: Adaptive Control Strategies for Cooperative Dual-Arm Manipulators, 653
—: Adaptive Force and Position Control of Manipulators, 551
—: Direct Adaptive Control of Manipulators in Cartesian Space, 157
Shaheen, M.: See Litvin, F. L.
Sliwinski, K. E.: See Ruokangas, C. C.

Thakor, N. V., and McNeela, M. A.: Application of a Dynamic Programming Algorithm for Trajectory Planning of Finger-Like Manipulators, 341
Tourassis, V. D.: See Ang, M. H., Jr.
—: See Neuman, C. P.

Tsai, Y. T., and Orin, D. E.: A Strictly Convergent Real-Time Solution for Invese Kinematics of Robot Manipulators, 477

Tzou, H. S., and Pandita, S.: A Multi-Purpose Dynamic and Tactile Sensor for Robot Manipulators, 719

Valavanis, K. P.: See Leahy, M. B., Jr.

Vira, N., and Lau, K.: An Extensive Ball Bar for Evaluation of Robots' Positioning Performance, 799

Wilhelm, W. E., Kalkunte, M., and Cash, C.: A Modeling Approach to Aid in Designing Robotized Manufacturing Cells, 25

Yuh, J.: Application of Discrete-Time Model Reference Adaptive Control to a Flexible Single-Link Robot, 621

Yurkovich, S.: See Özguner, Ü.

Zheng, Y. F.: Two Robot Arms in Assembly by Using Impulsive Information, 585